AMENDMENTS TO THE CLAIMS

1. (Currently Amended) A remote controlled robotic manipulator for manipulating a moving object comprising:

a motion sensor for sensing motion of a reference region of an object to be manipulated~~,~~;

and

a controller for locking motion of the robotic manipulator relative to the reference region of the object based on the sensed motion~~,~~;

wherein the ~~motion sensor~~ robotic manipulator, while locked in motion relative to the reference region, is arranged to ~~track~~ dynamically change the reference region to which its motion is locked to reflect movement in a visual fixation point of a user ~~to sense motion~~, and the controller is arranged to lock the motion of the robotic manipulator relative to different motions sensed at different regions of the object as the user visually fixates on different points of the object.

2. (Canceled)

3. (Canceled)

4. (Previously presented) A manipulator as claimed in claim 1 in which the user views a remote representation of the object.

5. (Currently Amended) A method ~~of~~ comprising:

identifying a visual fixation point of a user observing a stereo image formed by visually superposing two mono images of an object ~~comprising the steps of~~ by: presenting

~~one~~ a first mono image of the object to ~~each user~~ a first user eye and a second mono image of the object to a second user eye, to thereby form the stereo image; ~~and~~ tracking ~~the~~ a first fixation point ~~of each~~ in the first mono image for the first eye and a second fixation point in the second mono image for the second eye; and calculating a three-dimensional fixation point on the object based on the first fixation point and the second fixation point ~~with a motion sensor to sense motion of a region of an object in the stereo image~~;

wherein the first mono image and the second mono image are different images.

6. (Canceled)

7. (Currently Amended) An apparatus for identifying a fixation point in a stereo image comprising first and second displays for displaying different mono images of an object to individual eyes, a stereo image presentation module for visually super-posing the mono images to form the stereo image, ~~and an~~ a first and second eye tracker for tracking ~~a~~ fixation points of each individual eye relative to the mono image displayed to that eye; and a processor for calculating a three-dimensional position relative to the object based on the fixation points.

8. (Currently Amended) A manipulator as claimed in claim 1, wherein the reference region is within a human undergoing surgery and wherein the object is a tissue that is the subject of the surgery.

9. (Currently Amended) A manipulator as claimed in claim 1, wherein the controller dynamically determines the reference region of the object based on a signal from an eye tracking apparatus that tracks a visual fixation point of one or more eyes of a user.

10. (Currently Amended) A manipulator as claimed in claim ~~1~~ 9, wherein the eye tracking apparatus identifies the visual fixation point of the user who is observing a stereo image formed by visually superposing mono images, comprising the steps of presenting one mono image to each user eye to form the stereo image and tracking the fixation point of each eye.

11. (Previously presented) A manipulator as claimed in claim 8 in which a three-dimensional position of the visual fixation point is determined.

12. (Previously presented) A manipulator as claimed in claim 8, further comprising left and right LCD displays that display left and right images.

13. (Currently Amended) A method as claimed in claim ~~3~~ 5, wherein the first mono image~~s~~ and the second mono image are obtained from different sensors that are observing a human body as part of a surgery.

14. (Canceled)

15. (Currently Amended) An apparatus as recited in claim ~~5~~ 7, further comprising a remote controlled robotic manipulator for manipulating a moving object, a motion sensor for sensing motion of a reference region of an object to be manipulated, and a controller for locking

motion of the robotic manipulator relative to the reference region of the object based on the sensed motion, wherein the ~~motion sensor~~ robotic manipulator, while locked in motion relative to the reference region, is arranged to ~~track~~ dynamically change the reference region to which its motion is locked to reflect movement in a visual fixation point of a user ~~to sense motion~~, and the controller is arranged to lock the motion of the robotic manipulator relative to different motions sensed at different regions of the object as the user visually fixates on different points of the object.

16. (Canceled)

17. (Currently Amended) An apparatus as claimed in claim ~~13~~ 15, ~~wherein the eye tracker determines a three-dimensional position of the fixation point, and~~ wherein the robotic manipulator dynamically changes the reference region based on input from the eye tracker ~~controls the motion sensor~~ indicating the movement in the visual fixation point of the user.

18. (Currently Amended) An apparatus as claimed in claim ~~5~~ 7 in which a user views a remote representation of the object.

19. (Currently Amended) An apparatus as claimed in claim ~~13~~ 15, wherein the reference region is within a human undergoing surgery and wherein the object is an organ that is the subject of the surgery.

20. (Currently Amended) An apparatus as claimed in claim ~~5~~ 7, wherein each of the mono images depicts a region within a human undergoing surgery, and wherein the eye tracker tracks the fixation point of each eye of a surgeon.

21. (Currently Amended) An apparatus as claimed in claim 1 in which the ~~motion sensor~~ controller is arranged to determine a depth of the reference region to which the motion is to be locked based on a depth of ~~a~~ the visual fixation point.

22. (Currently Amended) An apparatus as claimed in claim ~~18~~ 21 in which ~~a~~ the depth of the visual fixation point is determined by an angle of a gaze of the user's eyes.